

# Reflection on path generation

1. Initially able to successfully build the project and opened the simulator.
2. As car is in stationary state, added code to have next x & y values at a regular interval of 0.5m and able to move the car at a regular intervals.
3. Car is able to move, but was running out of road and colliding with other cars.
4. And also had lot of jerks. By following the project Q & A lecture, was able to add code to generate points on a spline and use them to avoid jerks and also was able to stay on the road.
5. To eliminate collision issue, used the sensor fusion data and was able to slow down to avoid any collision and was moving to other lane to move ahead.
6. At this point when changing lane, I was colliding with traffic on the other lane.
7. To avoid the same, also started looking at the sensor fusion data of nearby cars in adjacent lanes.
8. Added code to move to other lanes only if no car is there nearby in that lane.

Able to run finally without any incident for 6 miles.

